LSR

UNIVERSITÄT DES SAARLANDES

Lehrstuhl für Systemtheorie und Regelungstechnik
Prof. Dr.-Ing. habil. J. Rudolph

Einladung

**Am Dienstag, 24.06.2014, 14.00 Uhr, findet
in Gebäude E2 9, Raum S0.07, ein Vortrag**

von

Herrn Dr. Martin Barczyk

Centre de Robotique, Mines ParisTech

zum Thema

Experimental Implementation of an Invariant Extended Kalman Filter-based Scan Matching SLAM

statt.

This talk describes an application of the Invariant Extended Kalman Filter (IEKF) design methodology to the scan matching SLAM problem. We describe the theoretical foundations of the IEKF and its practical interest of guaranteeing robustness to poor state estimates, then cover its implementation onboard a wheeled indoor robot hardware platform. The resulting filter is validated in experimental testing and also compared against a conventional EKF design.

Alle Interessenten sind herzlich eingeladen.

Prof. Dr.-Ing. habil. J. Rudolph